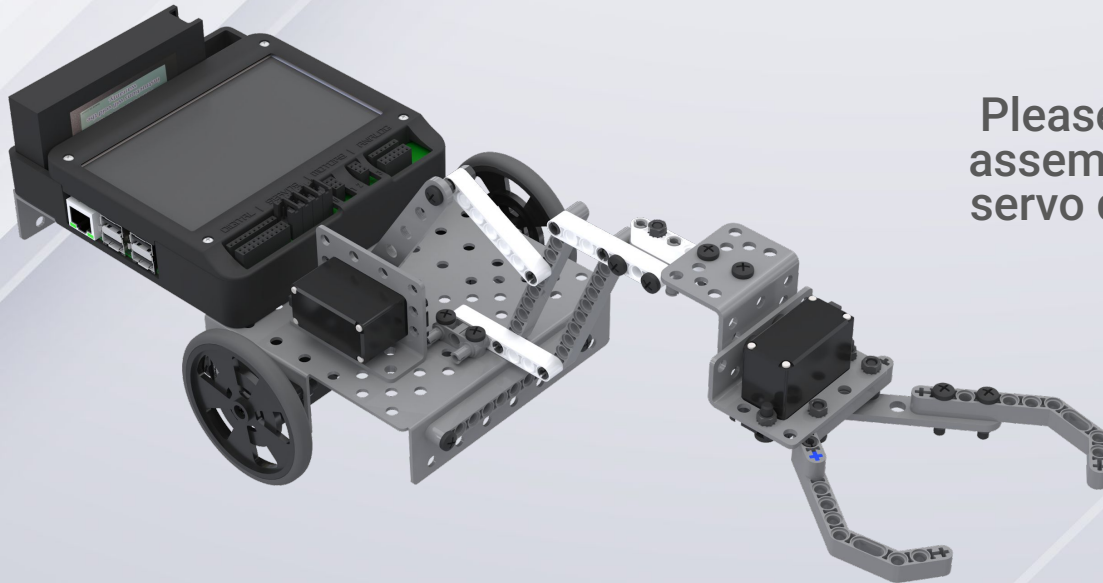
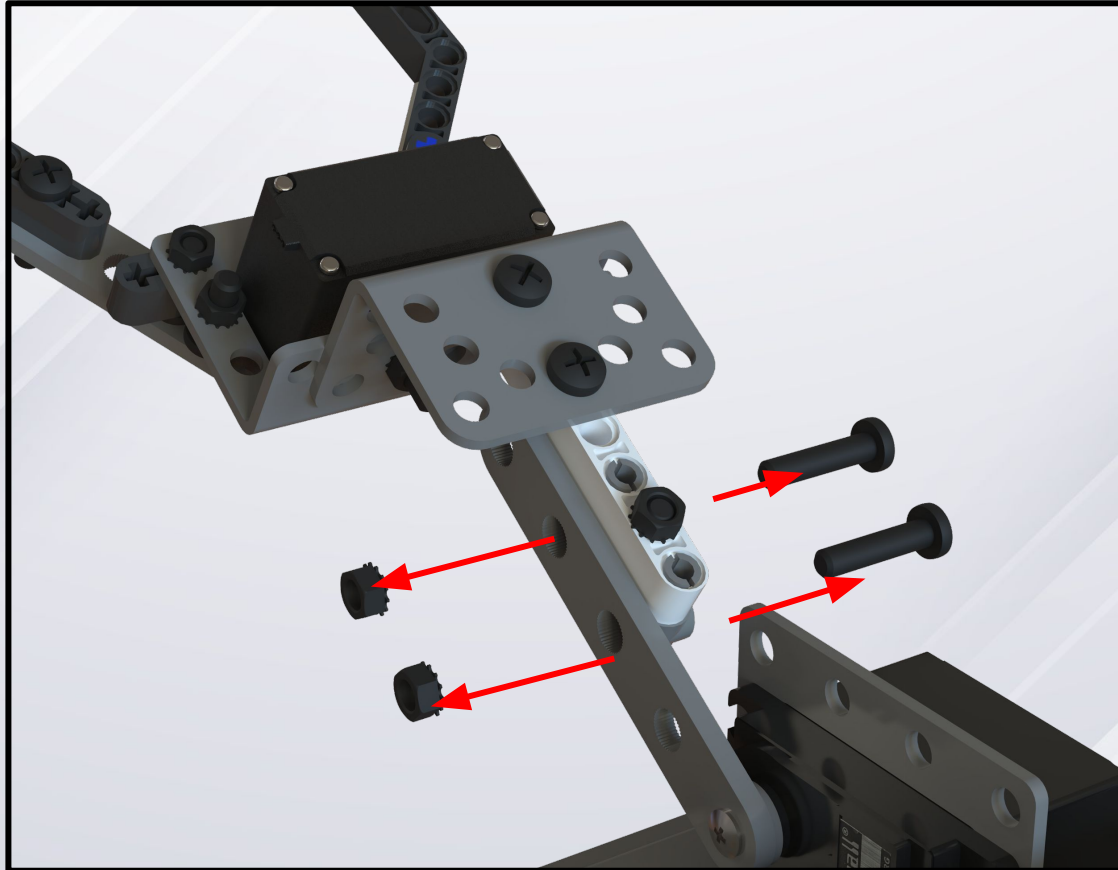


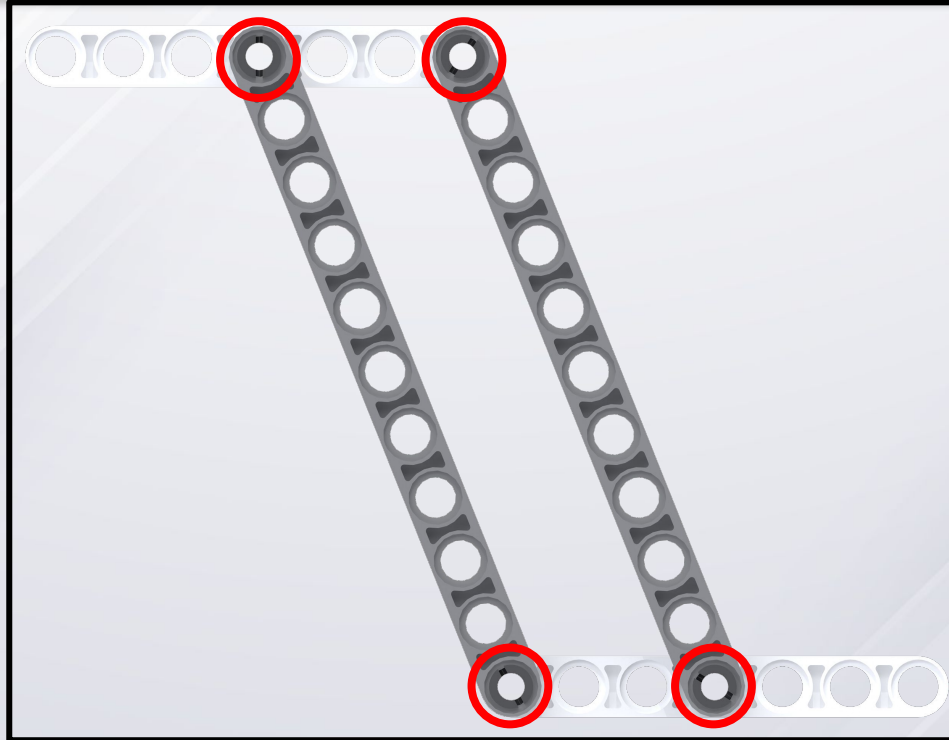
KIPR Paralleling Arm Demobot Build



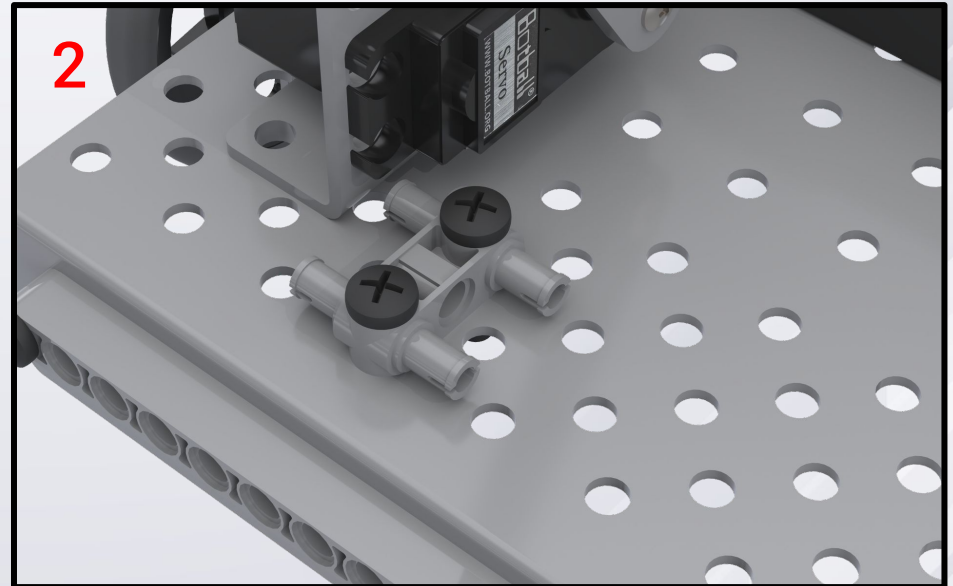
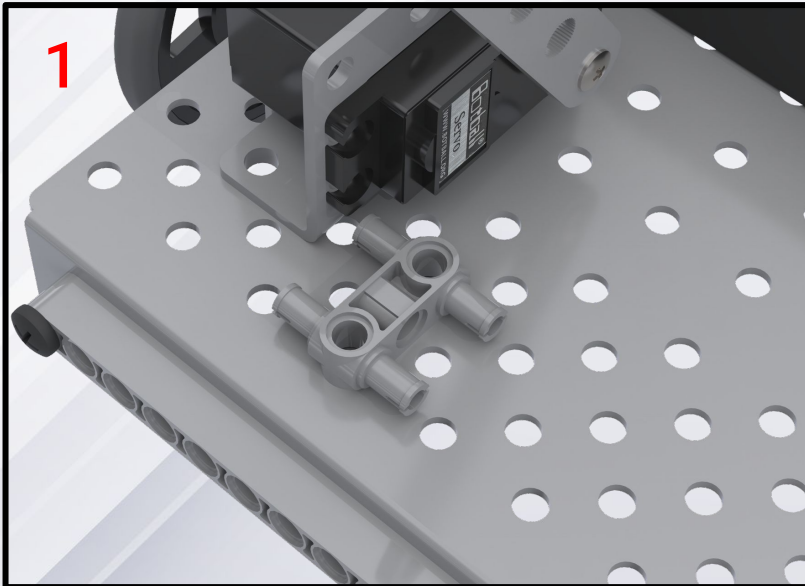
Please follow the slides to complete the assembly of your robot. This requires the servo demobot or the sensor demobot to be built.



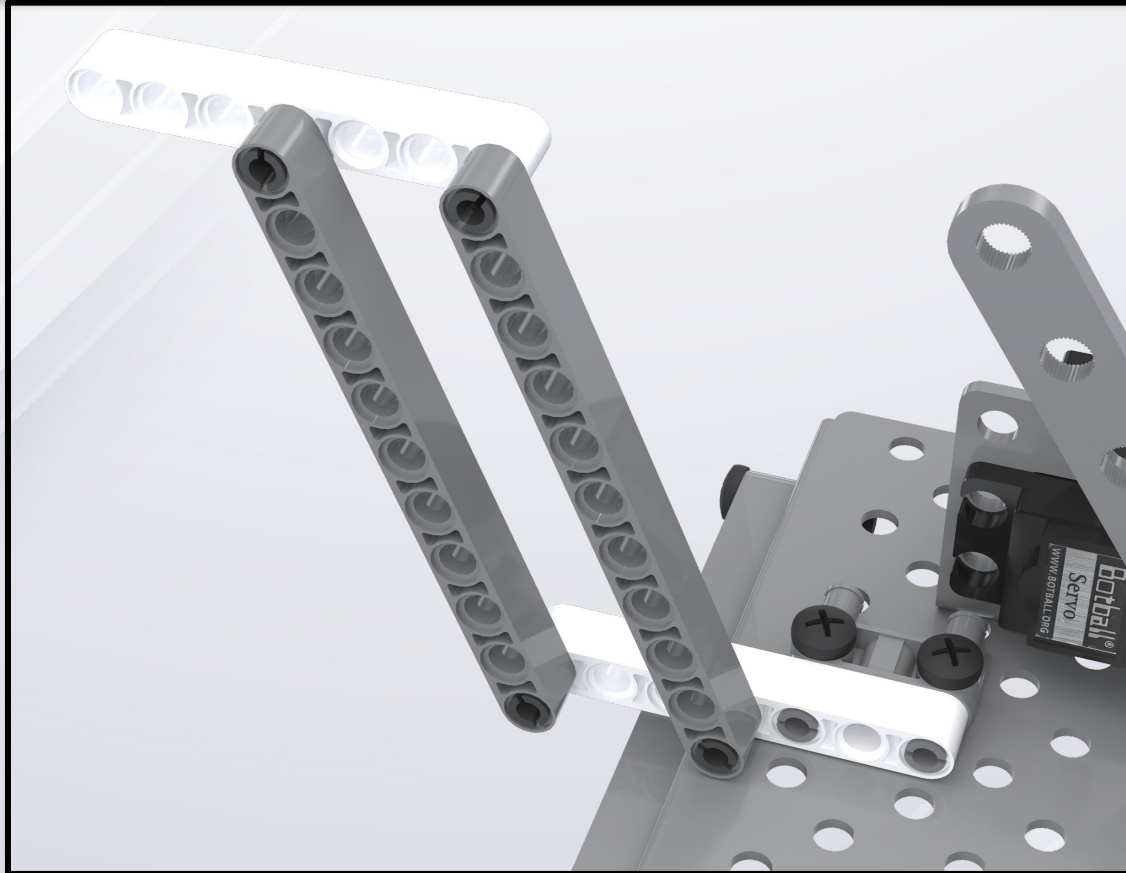
Detach the claw from the demobot where it is attached to the 1x5 Metal Servo Horn. Only the two long bolts need to be removed.



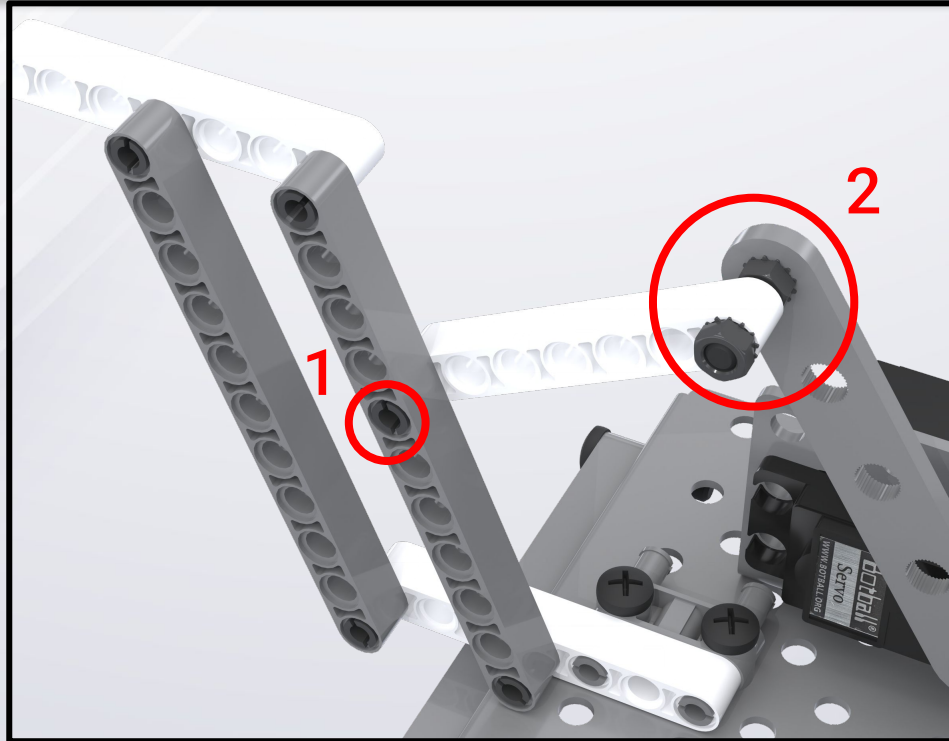
Take two 1x7 Lego Liftarms, two 1x11 Lego Liftarms, and 4 pins. Attach the 1x11 Liftarms on one side of the 1x7 Liftarms using the 4 pins on the holes shown. This design can be altered by using different lengths of Liftarms if desired.



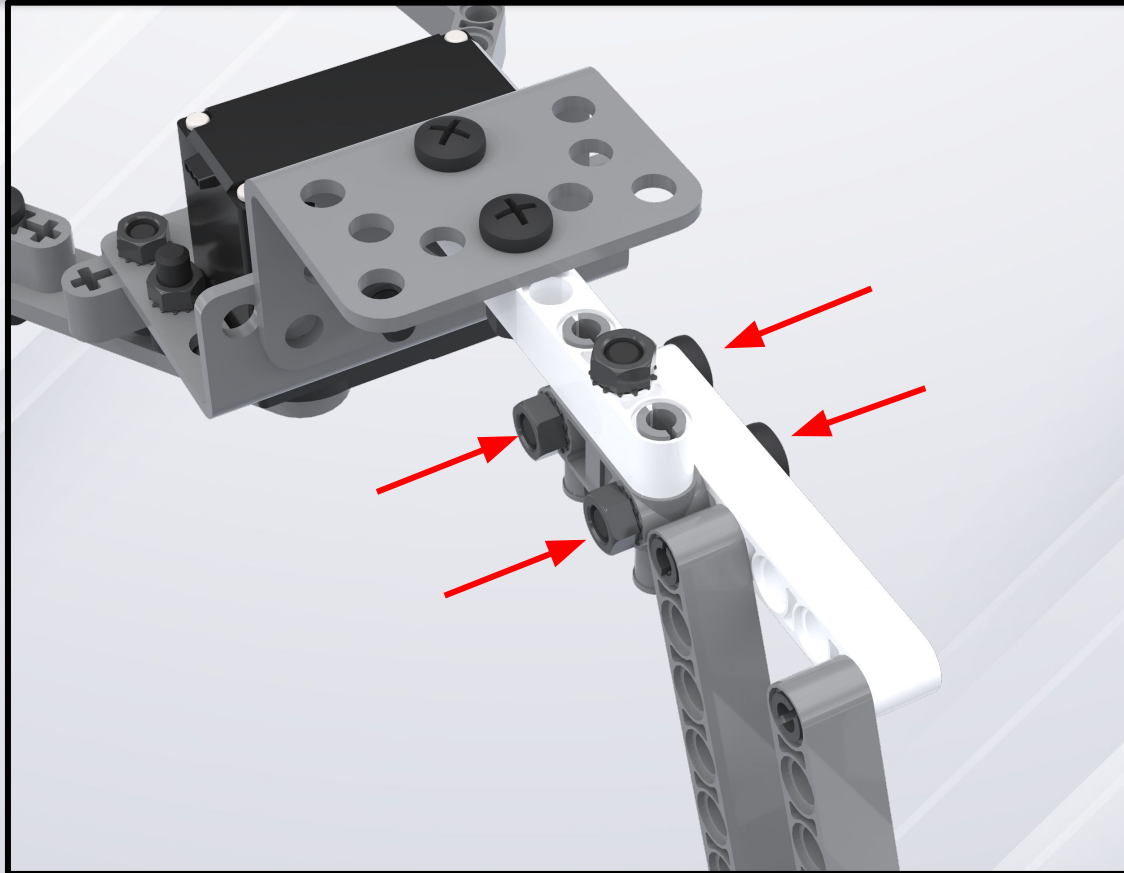
1. Position the H-pin on the demobot as shown. This will be used as the base for the paralleling arm.
2. Attach using medium or long bolts and nuts.



Attach the paralleling arm to the base. If you need to loosen and retighten the bolts holding the base, do so.



1. Using a 1x7 Lego Liftarm, attach it to the paralleling arm in the 5th hole from the top.
2. Using a long bolt and two nuts, screw the bolt onto the 1x5 Metal Servo Horn with one nut first, leaving it slightly loose. Then attach the other end of the 1x7 Liftarm and secure it with the other nut.



Reattach the claw to the end of the top 1x7 Liftarm using two long bolts and nuts.

Paralleling Arm Demobot Finished!

